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Search Results -

Term	Documents
HAPTIC	4885
HAPTICS	1891
COMMAND$3	0
COMMAND	545336
COMMANDA	43
COMMANDACK	4
COMMANDADD	3
COMMANDAN	1
COMMANDAND	11
COMMANDANT	77
COMMANDAR	1
((L2 OR L3) AND ((HAPTIC ADJ COMMAND$3) AND (ENABL$3 ADJ5 DISABL$3))).PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD.	2

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side		result set	
DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ			
L17	(l2 or l3) and ((haptic adj command$3) and (enabl$3 adj5 disabl$3))	2	L17
L16	(l2 or l3) and ((haptic adj command$3) and (enabl$3 adj3 disabl$3))	2	L16
L15	(l2 or l3) and ((haptic adj command$3) and (part adj3 data adj5 manag$5) and (enabl$3 adj3 disabl$3))	2	L15
L14	(l2 or l3) and ((haptic adj command$3) and (part adj3 data adj5 manag$5))	2	L14
L13	(l2 or l3) and ((haptic adj command$3) and (part adj3 data adj5 table))	2	L13
L12	(l2 or l3) and ((haptic adj command$3) and (part adj3 data))	5	L12
L11	(l2 or l3) and ((haptic adj commander))	2	L11
L10	(l2 or l3) and ((haptic adj commander) and (part adj3 data))	2	L10
L9	(l2 or l3) and ((haptic adj commander) and (data adj3 table))	2	L9
DB=EPAB; PLUR=YES; OP=ADJ			
L8	EP-1471410-A2.did.	0	L8
DB=PGPB; PLUR=YES; OP=ADJ			
L7	US-20040201605-A1.did.	1	L7
DB=JPAB; PLUR=YES; OP=ADJ			
L6	JP-2004319173-A.did.	1	L6
DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ			
L5	(l2 or l3) and ((haptic adj commander) and (data adj3 manag$5))	2	L5
L4	L3 and L2	1	L4
L3	(force adj feedback) and (input$4 adj device) and (position$3 adj3 detect$3 adj5 state)	5	L3
L2	(force adj feedback) and (input$4 adj device) and (haptic adj3 command$3)	38	L2
L1	(force adj feedback) and (input$4 adj device) and (position$3 adj3 detect$3 adj5 state) and (haptic adj3 command$3)	1	L1

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#3   (force feedback and input device<IN>metadata)

#4   (force feedback and input device<IN>metadata)

#5   (force feedback and input device<IN>metadata)

#6   ((force feedback input device haptic commander)<in>metadata)

#7   (matsumoto k.<in>au)

#8   (((matsumoto k.<in>au))<AND>(matsumoto k.<in>au) and (force
           feedback) and (input device))

#9   (((matsumoto k.<in>au))<AND>(matsumoto k.<in>au) and (force
           feedback) and (input device))

#10   (((((matsumoto k.<in>au))<and>(matsumoto k.<in>au) and
           (force feedback) and (input device)))<AND>(((matsumoto
           k.<in>au))<and>(matsumoto k.<in>au) and (force feedback) and
           (input device)) and (haptic commander))

#11   (((matsumoto k.<in>au))<AND>(matsumoto k.<in>au) and (force
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#13   (matsumoto k.<in>au)

#14   (((matsumoto k.<in>au))<AND>(haptic
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#15   (matsumoto k.<in>au)

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#17   (((matsumoto k.<in>au))<AND>(force feedback<in>metadata))

#18   (((matsumoto k.<in>au))<AND>(force feedback<in>metadata))

#19   (((matsumoto k.<in>au))<AND>(force feedback<in>metadata))

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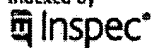|	
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          Penin, L.F.; Matsumoto, K.; Wakabayashi, S.;
          Robotics & Automation Magazine, IEEE
          Volume 7, Issue 4, Dec. 2000 Page(s):50 - 63
          Digital Object Identifier 10.1109/100.894033

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Robotics & Automation Magazine, IEEE
Volume 7, Issue 4, Dec. 2000 Page(s):50 - 63
Digital Object Identifier 10.1109/100.894033

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☐   **2. Force reflection for time-delayed teleoperation of Space robots**
Penin, L.F.; Matsumoto, K.; Wakabayashi, S.;
Robotics and Automation, 2000. Proceedings. ICRA '00. IEEE International Co
Volume 4, 24-28 April 2000 Page(s):3120 - 3125 vol.4
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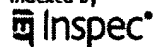
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Precision Electromagnetic Measurements, 1988. CPEM 88 Digest. 1988 Confe
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